

Amendments to the Claims:

This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

Claim 1 (currently amended): A drive device, ~~in particular for~~ for a robot arm (4) for a robot (R) which, ~~if appropriate,~~ is connected to a main drive (1) via at least one arm (2) such that it can be moved, wherein the robot arm (4) has a plurality of drive motors (M_1 to M_3) for swiveling ~~the~~ a housing (5) and, ~~if appropriate~~ optionally, for driving a spindle (6).

Claim 2 (original): The drive device as claimed in claim 1, wherein the drive motors (M_1 to M_3) are inserted into the housing (5) in an integrated manner.

Claim 3 (currently amended): The drive device as claimed in claim ~~1 or~~ 2, wherein the drive motors (M_1 to M_3) are integrated in receiving openings (14.1 to 14.3) of the housing 5 and are optionally designed as a shrunk or releasable connection.

Claim 4 (currently amended): The drive device as claimed in ~~at least one of claims 1 to 3~~ claim 1, wherein each drive motor (M_1 to M_3) is assigned a transmitter element (13), in particular a resolver, encoder or absolute value transmitter.

Claim 5 (currently amended): The drive device as claimed in ~~at least one of claims 1 to 4~~ claim 1, wherein an electromagnetically operated braking device (12) is assigned to the drive motor (M_1).

Claim 6 (currently amended): The drive device as claimed in ~~at least one of claims 1 to 5~~ claim 1, wherein the housing (5), in particular the robot arm (4), is connected to the arm (2) such that it can be swiveled about an axis (A_2), the drive motor (M_2) controlling a swiveling movement of the robot arm (4) with respect to the arm (2).

Claim 7 (currently amended): The drive device as claimed in ~~at least one of claims 1 to 6~~ claim 6, wherein in each case the two ~~further~~ drive motors (M_1 and M_3) are arranged close by in the region of the drive motor (M_2).

Claim 8 (currently amended): The drive device as claimed in ~~at least one of claims 1 to 7~~ claim 1, wherein a drive disk (9) of a linear guide, in particular the spindle (6), ~~can be~~ is driven by the drive motor (M_1) by means of a transmission element, ~~in particular belt element (11)~~.

Claim 9 (currently amended): The drive device as claimed in ~~at least one of claims 1 to 8~~ claim 8, wherein ~~the linear guide, in particular the spindle (6),~~ is constructed as a threaded spindle, ~~in particular as a~~ recirculating-ball spindle (7) having a groove (10) running in ~~the~~ a longitudinal direction.

Claim 10 (currently amended): The drive device as claimed in claim ~~8 or~~ 9, wherein the drive disk (9) engages in the groove (10) and, by means of being driven in rotation by the drive motor (M_1), permits a rotational movement of the spindle (6) about an axis (A_4).

Claim 11 (currently amended): The drive device as claimed in ~~at least one of claims 1 to 10~~ claim 1, wherein, in order to carry

out a lifting movement, a lifting disk (16) engages with the drive motor (M_3) via a transmission element, ~~in particular belt element (11),~~ at least one ~~ball element or pin~~ element engaging in spindle-like recesses in the spindle (6) in order to carry out a lifting movement as a result of rotation of the lifting disk (16).

Claim 12 (currently amended): The drive device as claimed in ~~at least one of claims 1 to 11~~ claim 1, wherein the drive motors (M_1 to M_4) are inserted into the housing (5) of the robot arm (4) in an integrated manner.

Claim 13 (currently amended): The drive device as claimed in ~~at least one of claims 1 to 12~~ claim 1, wherein the main drive (1) has a drive motor (M_5) which drives the arm (2) about an axis (A_5).

Claim 14 (currently amended): The drive device as claimed in ~~at least one of claims 1 to 13~~ claim 1, wherein motor shafts of the drive motors (M_1 to M_3) are mounted in the housing 5, ~~in particular inserted.~~

Claim 15 (currently amended): The drive device as claimed in ~~at least one of claims 1 to 14~~ claim 1, wherein stators of the drive motors (M_1 to M_3) are inserted into the receiving openings 14.1 to 14.3 in a ~~fixedly integrated or re-detachable~~ fixed manner.

Claim 16 (new): A robot comprises a main drive connected to an arm for driving the arm about an axis A_5 ; a robot arm connected to the arm, the robot arm comprises a housing and a spindle mounted in the housing; and drive means for driving the housing

at least about an axis A_2 of the arm and the spindle about an axis A_4 of the robot arm, the drive means comprises a plurality of drive motors.

Claim 17 (new): The robot as claimed in claim 16, wherein the drive motors are inserted into the housing (5) in an integrated manner.

Claim 18 (new): The robot as claimed in claim 1 or 2, wherein the drive motors (M_1 to M_3) are integrated in receiving openings of the housing 5 by a releasable connection.

Claim 19 (new): The robot as claimed in claim 16, wherein each drive motor is assigned a transmitter element comprising at least one of a resolver, encoder and absolute value transmitter.

Claim 20 (new): The robot as claimed in claim 16, wherein an electromagnetically operated braking device (12) is assigned to at least one of the drive motors.

Claim 21 (new): The robot as claimed in claim 16, wherein the housing is connected to the arm (2) such that it can be swiveled about the axis A_2 by one of the drive motors M_2 .

Claim 22 (new): The robot as claimed in claim 21, wherein two further drive motors M_1 and M_3 are arranged in the region of the drive motor M_2 .

Claim 23 (new): The robot as claimed in claim 22, wherein a drive disk for the particular spindle is driven by the drive motor M_1 by means of a transmission element.

Claim 24 (new): The robot as claimed in claim 16, wherein the spindle is constructed as a threaded, recirculating-ball spindle having a groove running in a longitudinal direction.

Claim 25 (new): The robot as claimed in claim 24, wherein a drive disk engages in the groove and, by means of being driven in rotation by the drive motor M_1 , permits a rotational movement of the spindle about the axis A_4 .

Claim 26 (new): The robot as claimed in claim 22, wherein, in order to carry out a lifting movement, a lifting disk engages with the drive motor (M_3) via a transmission element and at least one element engages in spindle-like recesses in the spindle to carry out a lifting movement as a result of rotation of the lifting disk.

Claim 27 (new): The robot as claimed in claim 16, wherein the drive motors are inserted into the housing of the robot arm in an integrated manner.

Claim 28 (new): The robot as claimed in claim 16, wherein the main drive has a drive motor M_5 which drives the arm about the axis A_5 .

Claim 29 (new): The robot as claimed in claim 22, wherein motor shafts of the drive motors M_1 to M_3 are mounted in the housing.

Claim 30 (new): The robot as claimed in claim 18, wherein stators of the drive motors M_1 to M_3 are inserted into the receiving openings in a re-detachable manner.